

Distributed By:
Signal Test, Inc
1529 Santiago Ridge Way
San Diego, CA 92154
Tel. 1-619-575-1577 USA
www.SignalTestInc.com
Sales@SignalTestInc.com



R680

The R680 Capabilities:

Programmable in C
via open source
WinAVR and
RobotLoader
software

Controllable from
keyboard

Controllable via
included RACS
software

Memory playback of
arm motion using
RACS

Expandable via the
I²C interface

Wireless control
options available

Banshi Robotic Arm



Overview:

The Banshi Robotic Arm is an affordable robot for the hobbyist. It is ideally suited to learn the basics of electronics, mechanics and programming. The Banshi is controlled by a powerful ATMEGA64 microcontroller that is programmable via open source tools in C.

The robot comes with many example programs already written. Easily download them to the robot using the supplied USB interface and the RobotLoader software. Or write your own custom programs using the free open-source WinAVR software.

Control the robot using the included keyboard or RACS software. Using the software you can record the movements of the Banshi and play them back.

The I/Os (in and outputs), together with the flexible I²C bus system, allow the addition of extra modules thus enabling the robot to react to its environment.

Features:

- Comes unassembled as a kit
- 6 DOF
- ATMEGA64 Processor
- Various available I/Os
- I²C Bus
- Easy downloads with RobotLoader Software
- Easy control with keyboard or RACS Software
- Plastic arm and metal chassis

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Banshi Robotic Arm

Banshi Robotic Arm comes with the following items:

Unassembled as a kit

Software CD with WinAVR, RobotLoader, and RACS.

Complete 72-page manual

Keyboard controller

USB connector cable

USB programmer interface

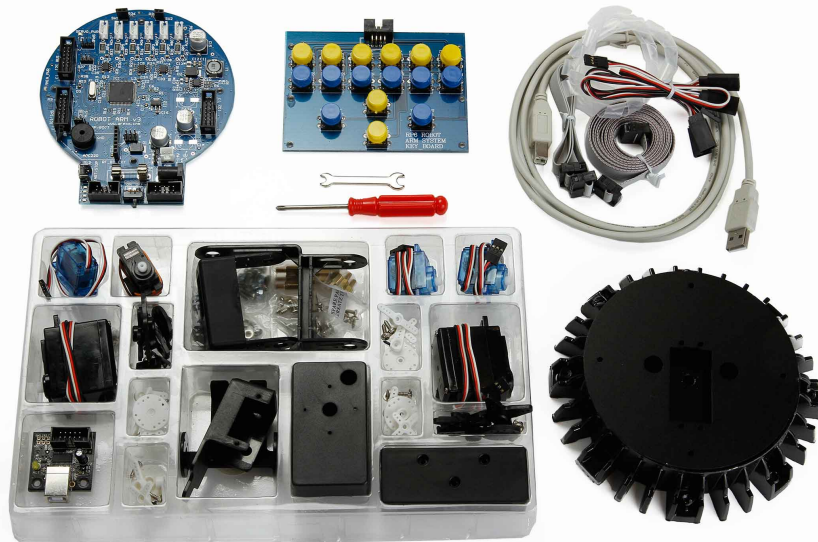
12V DC power supply

Assembly tools

Specifications:

Processor	ATMEGA64 8-bit microcontroller
Speed	16 MIPS
Memory	64KB Flash ROM, 4KB SRAM, 2KB EEPROM
Language	C
Expansion System	I ² C Bus
Communication	USB Cable to PC, Wireless Options Available
Arm Length	260 mm
Height (fully extended)	340 mm
Base Diameter	150 mm
Power Supply	9-14 V
Weight	1.3 lbs

Specifications subject to change without notice. Go to globalspecialties.com for the latest update.



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22820 Savi Ranch Parkway

globalspecialties.com

Yorba Linda, CA 92887

1.800.572.1028